

6. The transporter of claim 1 further comprising:
an axle associated with the at least one ground contacting element, the axle including a parallel orientation to a lateral axis of the transporter, the at least one of the plurality of support platforms being tiltable, in a fore-aft plane of the transporter, with respect to the axle.
7. The transporter of claim 1, wherein the torque comprises positive and negative values based on changes detected by the at least one sensor signal.
8. A transporter comprising;
a plurality of support platforms;
at least one ground contacting element coupled to the plurality of support platforms;
a motorized drive arrangement for driving the at least one ground contacting element;
at least one sensor generating at least one sensor signal indicative of an attitude of one of the plurality of support platforms; and
a controller commanding the motorized drive arrangement to apply a torque to one or more of the at least one ground contacting elements, the torque being based at least on a control algorithm, the control algorithm including the at least one sensor signal, the control algorithm being configured based at least on preferences of the user.
9. The transporter of claim 8, wherein the at least one ground contacting element comprises a first ground contacting element and a second ground contacting element.
10. The transporter of claim 8, further comprising a pivot mechanism tiltably attaching one of the plurality of support platforms to another of the plurality of support platforms.
11. The transporter of claim 8, wherein at least one of the plurality of support platforms tilting in a fore-aft plane relative to at least a portion of the transporter.
12. The transporter of claim 11, wherein the fore-aft plane comprises an orientation perpendicular to an axis of the at least one ground contacting element.

13. The transporter of claim 8, wherein one of the plurality of support platforms tilting relative to another of the plurality of support platforms.

14. The transporter of claim 8, wherein the at least one sensor signal sensing a tilt difference between one of the plurality of support platforms and another of the plurality of support platforms.

15. The transporter of claim 8, wherein the at least one ground contacting element comprises a first ground contacting element and a second ground contacting element, the first ground contacting element and second ground contacting element being laterally disposed.

16. The transporter of claim 15, wherein the motorized drive arrangement comprises a first motor driving the first ground contacting element and a second motor driving the second ground contacting element.

17. The transporter of claim 16, wherein the controller including determining, based at least in part on the at least one sensor signal, a desired first torque for the first motor separately from a desired second torque for the second motor.

18. The transporter of claim 17, wherein the desired first torque and the desired second torque comprise positive and negative values based on changes detected by the at least one sensor signal.

19. The transporter of claim 8, wherein the first ground contacting element and the second ground contacting element comprise wheels, the wheels rotating about a first wheel axle and a second wheel axle, at least one of the at least one sensor signals indicating a location of a fiducial point on the transporter, the fiducial point being in relation to at least one of the first wheel axle and the second wheel axle.

20. The transporter of claim 8, wherein the control algorithm including being configured based at least on current operating mode and operation conditions.

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